AMENDMENTS TO THE CLAIMS:

1. (Previously Presented) A rendering device for generating a drive assistant image of an area around a vehicle for drive assistance, said device comprising:

an image receiving part operable to receive images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;

a steering angle receiving part operable to receive a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;

a trajectory deriving part operable to derive an estimated trajectory for the vehicle to take based on the steering angle received by said steering angle receiving part; and

an image processing part operable to perform pixel selection from the captured images received by said image receiving part according to the steering angle received by said steering angle receiving part, and based on a result of the pixel selection, to generate the drive assistant image, wherein

if the estimated trajectory derived by said trajectory deriving part is designated over an overlapped region, said image processing part is operable to select pixels from a captured image received by said image receiving part representing one side of the overlapped region with respect to an imaginary line, and to select pixels from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the estimated trajectory.

2. (Previously Presented) The rendering device according to claim 1, further comprising a table storing part operable to store a mapping table showing a correspondence between the drive assistant image and the captured images on a pixel basis, wherein

in the mapping table, a pixel belonging to the overlapped region in the drive assistant image corresponds to a plurality of pixels in the captured images according to the steering angle received by said steering angle receiving part, and

according to the mapping table stored in said table storing part, said image processing part selects the pixels from each of the captured images received by said image receiving part.

3. (Previously Presented) The rendering device according to claim 1, further comprising:

a trajectory rendering part operable to render the estimated trajectory derived by said trajectory deriving part on the drive assistant image generated by said image processing part.

4. (Previously Presented) The rendering device according to claim 1, further comprising:

an image storing part operable to store a vehicle image representing the vehicle; and

a vehicle rendering part operable to render the vehicle image stored in said image storing part on the drive assistant image generated by said image processing part.

5. (Previously Presented) The rendering device according to claim 1, wherein said image processing part generates the drive assistant image showing the area around the vehicle viewed from a predetermined virtual camera.

6. (Previously Presented) A rendering method for generating a drive assistant image of an

area around a vehicle for drive assistance, said method comprising:

receiving images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;

receiving a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;

deriving an estimated trajectory for the vehicle to take based on the received steering angle; and

performing pixel selection from the received images according to the received steering angle, and based on a result of the pixel selection, generating the drive assistant image, wherein

if the estimated trajectory is designated an overlapped region, in said pixel selection, pixels are selected from a captured image representing one side of the overlapped region with respect to an imaginary line, and pixels are selected from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the estimated trajectory.

7. (Previously Presented) The rendering method according to claim 6, further comprising storing a mapping table showing a correspondence between the drive assistant image and the captured images on a pixel basis, wherein

in the mapping table, a pixel belonging to the overlapped region in the drive assistant image corresponds to a plurality of pixels in the captured images according to the received

steering angle, and

according to the stored mapping table, in said pixel selection, the pixels are selected from each of the received images.

8. (Previously Presented) A recording medium having a program recorded thereon for generating a drive assistant image of an area around a vehicle for drive assistance, said program including system readable instructions capable of instructing a system to perform the method comprising:

receiving images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;

receiving a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;

deriving an estimated trajectory for the vehicle to take based on the received steering angle; and

performing pixel selection from the received images according to the steering angle, and based on a result of the pixel selection, generating the drive assistant image, wherein

if the estimated trajectory is designated an overlapped region, in said pixel selection, pixels are selected from a captured image representing one side of the overlapped region with respect to an imaginary line, and pixels are selected from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the

estimated trajectory.

9. (Previously Presented) The recording medium having the program recorded thereon according to claim 8, further including system readable instructions capable of instructing a system to additionally store a mapping table showing a correspondence between the drive assistant image and the captured images on a pixel basis, wherein

in the mapping table, a pixel belonging to the overlapped region in the drive assistant image corresponds to a plurality of pixels in the captured images according to the received steering angle, and

according to the stored mapping table, in said pixel selection, the pixels are selected from each of the received captured images.

10-11. (Canceled)